

**IN THE CLAIMS:**

Please amend claims 27, 31 and 33 as follows:

1-26 (Cancelled).

27. (Currently amended) In a legged robot apparatus having a zero moment point (ZMP), a trunk having a movable part and an actuator for driving the movable part, a plurality of arms connected to the trunk, and a plurality of legs connected to the trunk, [[the]] a method of raising the robot apparatus from a fall-down posture on a floor by causing the zero moment point of the robot apparatus to move into the area where the legs contact the floor.

28. (Previously presented) The invention of Claim 27, wherein the legs have feet and the area where the legs contact the floor is the area where the feet contact the floor.

29. (Previously presented) The invention of Claim 27, wherein the movable part has a pitch axis and the actuator is a pitch axis actuator.

30. (Previously presented) The invention of Claim 28, wherein the robot has at least two arms and two legs, each leg has a knee and each foot has a sole; and wherein, the distance between the center of gravity G and the soles of the feet of the robot apparatus is made less than the lengths of the arms by bending the trunk and the legs to insert both knees between both arms in order to cause the ZMP to move into the area where the feet contact the floor.

31. (Currently amended) In a legged robot apparatus having a zero moment point (ZMP), a trunk having a movable part and an actuator for driving the movable part, a waist connected to the trunk, a plurality of arms connected to the trunk, and a plurality of legs connected to the waist, [[the]] a method of raising the robot apparatus from a supine position on a floor by moving to a posture where the waist is in contact with the floor, and making the distance between points of the arms which contact the floor and points of the legs which contact the floor shorter to cause the ZMP to move into the area where the legs contact the floor.

32. (Previously presented) A robot apparatus having a zero moment point (ZMP), a trunk and a plurality of movable parts which are connected to the trunk, said apparatus comprising:

a plurality of actuators for actuating the movable parts;

control means for controlling the actuators; and

means for moving said ZMP such that the robot apparatus gets up from a fall-down posture on a floor by causing the ZMP to move into an area at which the movable parts contact the floor.

33. (Currently amended) In a robot apparatus having a zero moment point (ZMP), a trunk and a plurality of movable parts which are connected to the trunk, a plurality of actuators for actuating the movable parts, and control means for controlling the actuators, [[the]] a method of raising the robot apparatus from a fall-down position on a floor by moving the ZMP into an area at which the movable parts contact the floor.